VEHICLE OPERATION PROCESSOR

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Inventor: SATO HIDEKI; SAKO HIDEKI
Applicant: DENSO CORP
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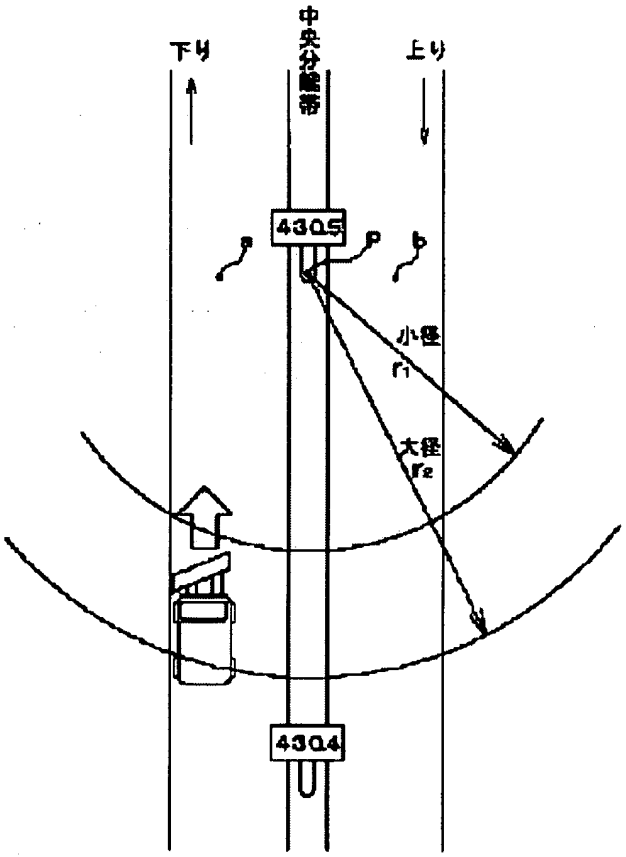
Abstract of **JP10241098**

PROBLEM TO BE SOLVED: To accurately detect the approach of a vehicle such as a snowplow to a target point in order to execute the accompanying processing of the target point by judging the approach of the snowplow to any one of target point sets, detecting a succeeding target point from a target point in the judged target point set based on relation with a precedently detected target point and executing the accompanying processing of the detected target point.
SOLUTION: Distance display posts are arranged on the median strip of a superhighway in each prescribed distance and it is supposed that a distance display post of '430.5' is set up. When a snowplow enters into a range of a radius r1 from a target point set P, a required target point out of target points (a), (b) included in the set P is detected. When a target point detected in the preceding detection is on a down lane, the cost of the target point (a) is minimum, so that the point (a) is detected as the succeeding target point. Then accompanying processing such as voice guidance and the automatic sampling of operation record is executed for the target point (a).



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(54) VEHICLE OPERATION PROCESSOR

(57) Abstract:

PROBLEM TO BE SOLVED: To accurately detect the approach of a vehicle such as a snowplow to a target point in order to execute the accompanying processing of the target point by judging the approach of the snowplow to any one of target point sets, detecting a succeeding target point from a target point in the judged target point set based on relation with a precedently detected target point and executing the accompanying processing of the detected target point.

SOLUTION: Distance display posts are arranged on the median strip of a superhighway in each prescribed distance and it is supposed that a distance display post of '430.5' is set up. When a snowplow enters into a range of a radius r_1 from a target point set P, a required target point out of target points (a), (b) included in the set P is detected. When a target point detected in the preceding detection is on a down lane, the cost of the target point (a) is minimum, so that the point (a) is detected as the succeeding target point. Then accompanying processing such as voice guidance and the automatic sampling of operation record is executed for the target point (a).